Amendments to the Abstract:

~~The invention relates to a~~ <u>A</u> method for calibration of a working point (TCP) for tools ~~(13)~~ on industrial robots ~~(8)~~ with a calibration device[[.]] ~~(1), comprising~~ <u>includes the use of</u> at least two light barriers with an azimuth angle (α) greater than zero at an angle to each other and intersecting at an intersection point. ~~(R), comprising~~ <u>The method includes</u> ~~the steps: a)~~ fixing set TCP positional coordinates for a set working point ~~(TCP<SB>SOLL</SB>)~~ for the tool ~~(13)~~, relative to a tool reference point ~~(W)~~ ~~of the industrial robot (8)~~ and a TCP coordinate system relative to the working point ~~(TCP)~~, ~~b)~~ moving the tool ~~(13)~~ ~~directly~~ to the set working point with relation to the TCP coordinate system through the light barriers, such that the tool tip ~~of the tool (13), corresponding to the working point (TCP),~~ interrupts the light [[E]] barriers[[.]], ~~c)~~ recording actual TCP positional coordinates ~~on interruption of a light barrier, d)~~ ~~determination of~~ <u>determining</u> the difference between the set TCP positional coordinates for the interruption of the light barriers for a set working point ~~(TCP<SB>SOLL<SB>)~~ and the corresponding recorded actual TCP positional coordinates for the actual working point ~~(TCP<SB>IST</SB>)~~, ~~e) calculation of deviation of~~ <u>calculating</u> the actual working point ~~(TCP<SB>IST</SB>)~~ from the set working point ~~(TCP<SB>SOLL<ISB>)~~ for the number of levels ~~as defined by the~~ <u>of</u> light barriers from the differences and the known position and azimuth angles (a) of the light barriers.